

IN THE CLAIMS

Please amend claims 1, 2, 4, 17 and 20, and add claims 21-25
as follows:

1 1. (Currently Amended) A linear method for performing head
2 motion estimation from facial feature data, the method comprising
3 the steps of:

4 obtaining a first facial image and detecting a head in said
5 first image;

6 detecting position of not more than four points P of said
7 first facial image where $P = \{p_1, p_2, p_3, p_4\}$, and $p_k = (x_k, y_k)$;

8 obtaining a second facial image and detecting a head in said
9 second image;

10 detecting position of not more than four points P' of said
11 first facial image where $P' = \{p'_1, p'_2, p'_3, p'_4\}$ and $p'_k = (x'_k, y'_k)$; and

12 determining the motion of the head represented by a rotation
13 matrix R and translation vector T using said points P and P' .

1 2. (Currently Amended) The linear method of claim 1, wherein
2 said four points P of said first facial image and said four points

3 P' of said second facial image include locations of outer corners
4 of each eye and mouth of each respective first and second facial
5 images.

1 3.(Original) The linear method of claim 1, wherein said head
2 motion estimation is governed according to:

3
$$\mathbf{P}'_i = R\mathbf{P}_i + \mathbf{T}, \text{ where } R = \begin{bmatrix} \mathbf{r}_1^T \\ \mathbf{r}_2^T \\ \mathbf{r}_3^T \end{bmatrix} = [\mathbf{r}_{ij}]_{3 \times 3} \text{ and } \mathbf{T} = [T_1 \ T_2 \ T_3]^T \text{ represent camera}$$

4 rotation and translation respectively, said head pose estimation
5 being a specific instance of head motion estimation.

1 4.(Currently Amended) ~~The linear method of claim 3~~ A linear
2 method for performing head motion estimation from facial feature
3 data, the method comprising the steps of:

4 obtaining a first facial image and detecting a head in said
5 first image;

6 detecting position of four points P of said first facial image
7 where $P = \{p_1, p_2, p_3, p_4\}$, and $p_k = (x_k, y_k)$;

8 obtaining a second facial image and detecting a head in said
9 second image;

10 detecting position of four points P' of said first facial
11 image where $P' = \{p'_1, p'_2, p'_3, p'_4\}$ and $p'_k = (x'_k, y'_k)$; and,
12 determining the motion of the head represented by a rotation
13 matrix R and translation vector T using said points P and P' ,
14 wherein said head motion estimation is governed according to:

15 $P'_i = RP_i + T$, where $R = \begin{bmatrix} r_1^T \\ r_2^T \\ r_3^T \end{bmatrix} = [r_{ij}]_{3 \times 3}$ and $T = [T_1 \ T_2 \ T_3]^T$ represent camera

16 rotation and translation respectively, said head pose estimation
17 being a specific instance of head motion estimation, and

18 wherein said head motion estimation is governed according to
19 said rotation matrix R , said method further comprising the steps
20 of:

21 determining rotation matrix R that maps points P_k to F_k for
22 characterizing a head pose, said points F_1, F_2, F_3, F_4 representing three-
23 dimensional (3-D) coordinates of the respective four points of a
24 reference, frontal view of said facial image, and P_k is the three-
25 dimensional (3-D) coordinates of an arbitrary point where

26 $P_i = [X_i \ Y_i \ Z_i]^T$, said mapping governed according to the relation:

$$R(\mathbf{P}_2 - \mathbf{P}_1) \propto [1 \ 0 \ 0]^T$$

28 $R(\mathbf{P}_6 - \mathbf{P}_5) \propto [0 \ 1 \ 0]^T$

29

30 wherein P_5 and P_6 are midpoints of respective line segments
31 connecting points P_1P_2 and P_3P_4 and, line segment connecting points
32 P_1P_2 is orthogonal to a line segment connecting points P_5P_6 , and
33 \propto indicates a proportionality factor.

1 5. (Original) The linear method of claim 4, wherein
2 components r_1 , r_2 and r_3 are computed as:

$$\mathbf{r}_2^T (\mathbf{P}_2 - \mathbf{P}_1) = 0$$

3 $\mathbf{r}_3^T (\mathbf{P}_2 - \mathbf{P}_1) = 0$

$$\mathbf{r}_1^T (\mathbf{P}_6 - \mathbf{P}_5) = 0$$

$$\mathbf{r}_3^T (\mathbf{P}_6 - \mathbf{P}_5) = 0$$

1 6. (Original) The linear method of claim 5, wherein
2 components r_1 , r_2 and r_3 are computed as:

3 $\mathbf{r}_3 = (\mathbf{P}_6 - \mathbf{P}_5) \times (\mathbf{P}_2 - \mathbf{P}_1),$

4 $\mathbf{r}_2 = \mathbf{r}_3 \times (\mathbf{P}_2 - \mathbf{P}_1)$

$$\mathbf{r}_1 = \mathbf{r}_2 \times \mathbf{r}_3$$

1 7.(Original) The linear method of claim 4, wherein

$$\begin{bmatrix} \mathbf{P}_i^T & \mathbf{0}^T & \mathbf{0}^T & 1 & 0 & 0 \\ \mathbf{0}^T & \mathbf{P}_i^T & \mathbf{0}^T & 0 & 1 & 0 \\ \mathbf{0}^T & \mathbf{0}^T & \mathbf{P}_i^T & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \mathbf{r}_1 \\ \mathbf{r}_2 \\ \mathbf{r}_3 \\ \mathbf{T} \end{bmatrix} = \mathbf{P}_i'$$

2
3 each point pair yielding 3 equations, whereby at least four
4 point pairs are necessary to linearly solve for said rotation and
5 translation.

1 8.(Original) The linear method of claim 7, further comprising
2 the step of: decomposing said rotation matrix R using Singular
3 Value Decomposition (SVD) to obtain a form $R = USV^T$.

1 9.(Original) The linear method of claim 7, further comprising
2 the step of computing a new rotation matrix according to $R = UV^T$.

1 10.(Original) A linear method for performing head motion
2 estimation from facial feature data, the method comprising the
3 steps of:

4 obtaining image position of four points \mathbf{P}_k of a facial image;

determining a rotation matrix R that maps points \mathbf{P}_k to \mathbf{F}_k for characterizing a head pose, said points $\mathbf{F}_1, \mathbf{F}_2, \mathbf{F}_3, \mathbf{F}_4$ representing three-dimensional (3-D) coordinates of the respective four points of a reference, frontal view of said facial image, and \mathbf{P}_k is the three-dimensional (3-D) coordinates of an arbitrary point where $\mathbf{P}_i = [X_i \ Y_i \ Z_i]^T$, said mapping governed according to the relation:

$$\begin{aligned} R(\mathbf{P}_2 - \mathbf{P}_1) &\propto [1 \ 0 \ 0]^T \\ R(\mathbf{P}_6 - \mathbf{P}_5) &\propto [0 \ 1 \ 0]^T \end{aligned}$$

wherein P_5 and P_6 are midpoints of respective line segments connecting points P_1P_2 and P_3P_4 and, line segment connecting points P_1P_2 is orthogonal to a line segment connecting points P_5P_6 , and \propto indicates a proportionality factor.

11. (Original) The linear method of claim 10, wherein components r_1 , r_2 and r_3 are computed as:

$$\begin{aligned} \mathbf{r}_2^T (\mathbf{P}_2 - \mathbf{P}_1) &= 0 \\ \mathbf{r}_3^T (\mathbf{P}_2 - \mathbf{P}_1) &= 0 \\ \mathbf{r}_1^T (\mathbf{P}_6 - \mathbf{P}_5) &= 0 \\ \mathbf{r}_3^T (\mathbf{P}_6 - \mathbf{P}_5) &= 0 \end{aligned}$$

12.(Original) The linear method of claim 11, wherein
components r_1 , r_2 and r_3 are computed as:

$$\mathbf{r}_3 = (\mathbf{P}_6 - \mathbf{P}_5) \times (\mathbf{P}_2 - \mathbf{P}_1),$$

$$\mathbf{r}_2 = \mathbf{r}_3 \times (\mathbf{P}_2 - \mathbf{P}_1)$$

$$\mathbf{r}_1 = \mathbf{r}_2 \times \mathbf{r}_3$$

13.(Original) The linear method of claim 12, wherein a motion
of head points is represented according to $\mathbf{P}'_i = \mathbf{R}\mathbf{P}_i + \mathbf{T}$

$$\mathbf{R} = \begin{bmatrix} \mathbf{r}_1^T \\ \mathbf{r}_2^T \\ \mathbf{r}_3^T \end{bmatrix} = [\mathbf{r}_{ij}]_{3 \times 3}$$

where \mathbf{R} represents image rotation, $\mathbf{T} = [T_1 \ T_2 \ T_3]^T$

represents translation, and \mathbf{P}'_i denotes a 3-D image position of four
points \mathbf{P}_k of another facial image

14.(Original) The linear method of claim 13, wherein

$$\begin{bmatrix} \mathbf{P}_i^T & \mathbf{0}^T & \mathbf{0}^T & 1 & 0 & 0 \\ \mathbf{0}^T & \mathbf{P}_i^T & \mathbf{0}^T & 0 & 1 & 0 \\ \mathbf{0}^T & \mathbf{0}^T & \mathbf{P}_i^T & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \mathbf{r}_1 \\ \mathbf{r}_2 \\ \mathbf{r}_3 \\ \mathbf{T} \end{bmatrix} = \mathbf{P}'_i,$$

3 each point pair yielding 3 equations, whereby at least four
4 point pairs are necessary to linearly solve for said rotation and
5 translation.

1 15.(Original) The linear method of claim 14, further
2 comprising the step of: decomposing said rotation matrix R using
3 Singular Value Decomposition (SVD) to obtain a form $R = USV^T$.

1 16.(Original) The linear method of claim 15, further
2 comprising the step of computing a new rotation matrix according to
3 $R = UV^T$.

1 17.(Currently Amended) A program storage device readable by
2 machine, tangible embodying a program of instructions executable by
3 the machine to perform method steps for performing head motion
4 estimation from facial feature data, the method comprising the
5 steps of:

6 obtaining a first facial image and detecting a head in said
7 first image;

8 detecting position of not more than four points P of said
9 first facial image where $P = \{p_1, p_2, p_3, p_4\}$, and $p_k = (x_k, y_k)$;
10 obtaining a second facial image and detecting a head in said
11 second image;
12 detecting position of not more than four points P' of said
13 first facial image where $P' = \{p'_1, p'_2, p'_3, p'_4\}$ and $p'_k = (x'_k, y'_k)$; and,
14 determining the motion of the head represented by a rotation
15 matrix R and translation vector T using said points P and P'.

1 18.(Original) The program storage device readable by machine
2 as claimed in claim 17, wherein said four points P of said first
3 facial image and four points P' of said second facial image include
4 locations of outer corners of each eye and mouth of each respective
5 first and second facial image.

1 19.(Original) The program storage device readable by machine
2 as claimed in claim 17, wherein said head motion estimation is
3 governed according to:

4 $\mathbf{P}'_i = R\mathbf{P}_i + \mathbf{T}$, where $R = \begin{bmatrix} \mathbf{r}_1^T \\ \mathbf{r}_2^T \\ \mathbf{r}_3^T \end{bmatrix} = [r_{ij}]_{3 \times 3}$ and $\mathbf{T} = [T_1 \ T_2 \ T_3]^T$ represent
5 camera rotation and translation respectively, said head pose
6 estimation being a specific instance of head motion estimation.

1 20. (Currently Amended) ~~The~~ A program storage device readable
2 by machine as claimed in claim 19, tangible embodying a program of
3 instructions executable by the machine to perform method steps for
4 performing head motion estimation from facial feature data, the
5 method comprising the steps of:
6 obtaining a first facial image and detecting a head in said
7 first image;
8 detecting position of four points P of said first facial image
9 where $P = \{P_1, P_2, P_3, P_4\}$, and $P_k = (x_k, y_k)$;
10 obtaining a second facial image and detecting a head in said
11 second image;
12 detecting position of four points P' of said first facial
13 image where $P' = \{p'_1, p'_2, p'_3, p'_4\}$ and $p'_k = (x'_k, y'_k)$; and

14 determining the motion of the head represented by a rotation
 15 matrix R and translation vector T using said points P and P' ,
 16 wherein said head motion estimation is governed according to:

$$R = \begin{bmatrix} \mathbf{r}_1^T \\ \mathbf{r}_2^T \\ \mathbf{r}_3^T \end{bmatrix} = [r_{ij}]_{3 \times 3} \quad \text{and} \quad \mathbf{T} = [T_1 \quad T_2 \quad T_3]^T \quad \text{represent}$$

17 $\mathbf{P}'_i = R\mathbf{P}_i + \mathbf{T}$, where

18 camera rotation and translation respectively, said head pose
 19 estimation being a specific instance of head motion estimation, and

20 wherein said head pose estimation is governed according to
 21 said rotation matrix R, said method further comprising the steps
 22 of:

23 determining rotation matrix R that maps points \mathbf{P}_k to \mathbf{F}_k for
 24 characterizing a head pose, said points $\mathbf{F}_1, \mathbf{F}_2, \mathbf{F}_3, \mathbf{F}_4$ representing three-
 25 dimensional (3-D) coordinates of the respective four points of a
 26 reference, frontal view of said facial image-, and \mathbf{P}_k is the three-
 27 dimensional (3-D) coordinates of an arbitrary point where

28 $\mathbf{P}_i = [X_i \quad Y_i \quad Z_i]^T$, said mapping governed according to the relation:

$$R(\mathbf{P}_2 - \mathbf{P}_1) \propto [1 \quad 0 \quad 0]^T$$

$$R(\mathbf{P}_6 - \mathbf{P}_5) \propto [0 \quad 1 \quad 0]^T$$

31

32 wherein P_5 and P_6 are midpoints of respective line segments
33 connecting points P_1P_2 and P_3P_4 and, line segment connecting points
34 P_1P_2 is orthogonal to a line segment connecting points P_5P_6 , and
35 \propto indicates a proportionality factor.

1 21. (New) The program storage device readable by machine as
2 claimed in claim 20, wherein components r_1 , r_2 and r_3 are computed
3 as:

$$r_2^T (P_2 - P_1) = 0$$

$$r_3^T (P_2 - P_1) = 0$$

$$r_1^T (P_6 - P_5) = 0$$

4 $r_3^T (P_6 - P_5) = 0$

1

1 22. (New) The program storage device readable by machine as
2 claimed in claim 20, wherein components r_1 , r_2 and r_3 are computed
3 as:

4 $r_3 = (P_6 - P_5) \times (P_2 - P_1) ,$

$$r_2 = r_3 \times (P_2 - P_1)$$

5 $r_1 = r_2 \times r_3$

1

1 23. (New) The program storage device readable by machine as
2 claimed in claim 20, wherein

$$3 \quad \begin{bmatrix} \mathbf{P}_i^T & \mathbf{0}^T & \mathbf{0}^T & 1 & 0 & 0 \\ \mathbf{0}^T & \mathbf{P}_i^T & \mathbf{0}^T & 0 & 1 & 0 \\ \mathbf{0}^T & \mathbf{0}^T & \mathbf{P}_i^T & 0 & 0 & 1 \end{bmatrix} \begin{bmatrix} \mathbf{r}_1 \\ \mathbf{r}_2 \\ \mathbf{r}_3 \\ \mathbf{T} \end{bmatrix} = \mathbf{P}_i'$$

4 each point pair yielding 3 equations, whereby at least four
5 point pairs are necessary to linearly solve for said rotation and
6 translation.

24. (New) The program storage device readable by machine as
claimed in claim 23, further comprising the steps of decomposing
said rotation matrix R using Singular Value Decomposition (SVD) to
obtain a form $R = USV^T$.

25. (New) The program storage device readable by machine as
claimed in claim 23, further comprising the steps of computing a
new rotation matrix according to $R = UV^T$.